## DG01D-E motor with encoder

Specification:
Dimension: 80x22.4x25.8mm
Voltage:3V~9V
Gear ratio:1:48
Speed:90RPM (4.5V)
Color :blue color
Gear material: metal

Dimension drawing:


## 1.Encoder board specification

Board size: 26*22*1.2mm
2. Terminal pin definition:

G: hall power negative;
H 1 : hall H 1 output signal, square wave;
H 2 : hall H 2 output signal, square wave;
V : hall power positive;
$\mathrm{M}+$ : motor positive pole;
M -: motor negative pole;
Remark: 1. The voltage between V-G is determined according to the power supply voltage of the single chip microcomputer used, generally 3.3 V or 5 V is used.
2. The frequency of the output square wave of H 1 and H 2 and the speed of the motor are related to the number of poles of the used magnetic disk.
3. The voltage between $M+$ and $M$ - is set according to the motor voltage used.

## 3. Principle

3.1 Motor speed measurement: The Hall sensor can sense the N and S poles of the magnetic plate. We use the Hall of the S pole to sense that when each Hall sensor senses the $S$ of the magnetic plate, the Hall output will output a high level; When the N pole of the magnetic plate, the Hall output will output a low level. When the motor rotates continuously, a square wave is output at the Hall output. The speed of the motor can be known based on the period $T$ of the output square wave. Assuming that the magnetic disk we use is the P-polarity, the measured square-wave period is $T$. Measure motor speed: $n=60 / P T$.
3.2 Motor reversal measurement: Two Hall sensors are placed in two different positions in the circuit. When the motor turns differently, the two Hall outputs have different square waves.
When the motor rotates forward, H 1 detects the rising edge, H 2 enters the falling edge; when the motor reverses, H 1 detects the falling edge, H 2 is also the falling edge.



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